

# Rotary Percussive Sample Acquisition Tool (SAT): Hardware Development and Testing

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Kerry Klein, Mircea Badescu, Nicolas Haddad, Lori Shiraishi, and Phillip Walkemeyer

Jet Propulsion Laboratory  
California Institute of Technology

## Introduction

## Hardware Development

## Lessons Learned – Hardware Dev

## Test Results

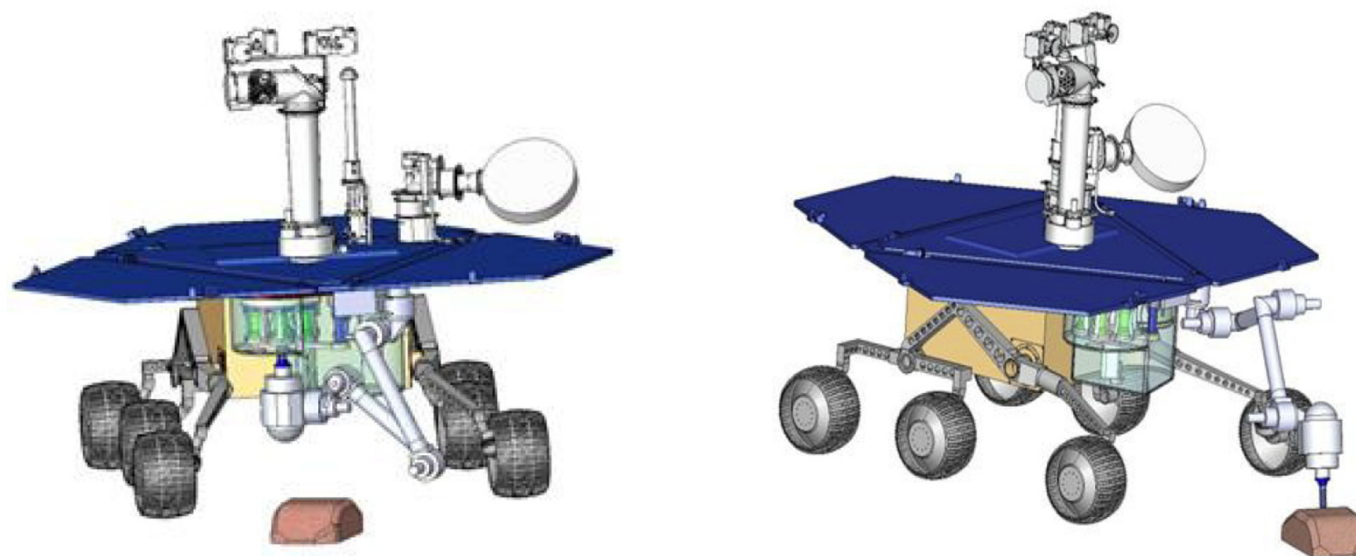
## Lessons Learned – Unit Testing

## Conclusion

The work was performed as part of a potential Mars Sample Return (MSR) campaign



It is foreseen that a **Sample Acquisition and Caching (SAC)** subsystem would be necessary for acquiring and storing samples



*Artist's Concept Rover based SAC Subsystem*

## Introduction

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## Lessons Learned – Unit Testing

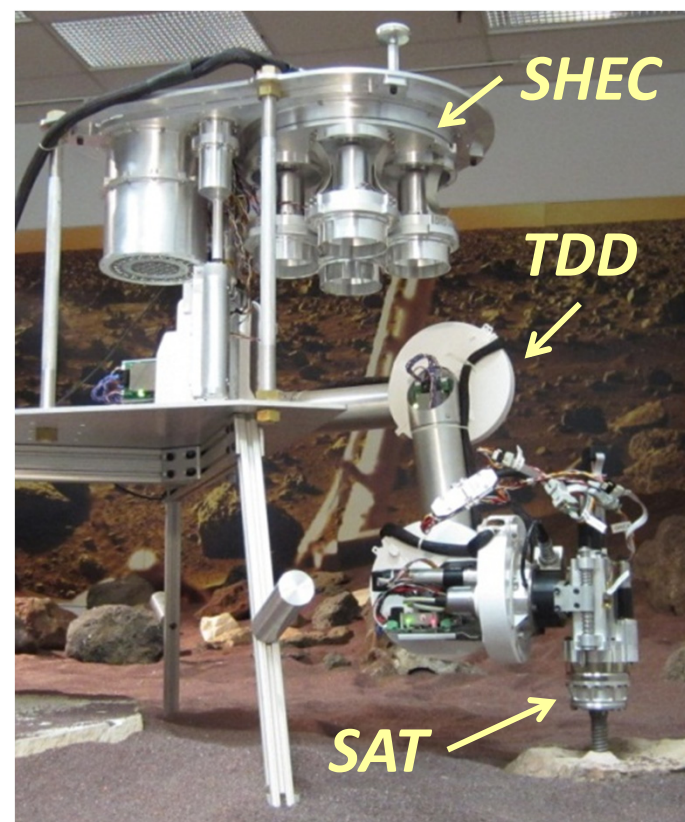
## Conclusion

**Integrated Mars Sample Acquisition and Handling (IMSAH)** architecture has been proposed to satisfy potential SAC subsystem needs



Three main sub-elements:

- 1) Tool Deployment Device (TDD)
- 2) Sample Handling Encapsulation and Containerization (SHEC)
- 3) Sample Acquisition Tool (SAT)



*IMSAH Hardware*

## Introduction

## Hardware Development

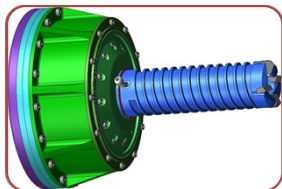
## Lessons Learned – Hardware Dev

## Test Results

## Lessons Learned – Unit Testing

## Conclusion

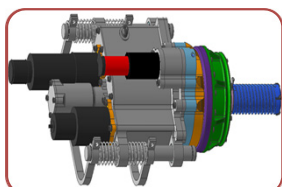
Key enabling **IMSAH** elements that allow for autonomous coring and caching:



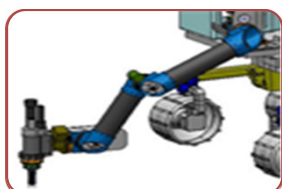
bit change-out for sample transfer



Core directly into individual sample tubes



Rotary Percussive Coring Tool (SAT) allows for reduced tool preload



5-DOF Robotic Arm (TDD) with force feedback

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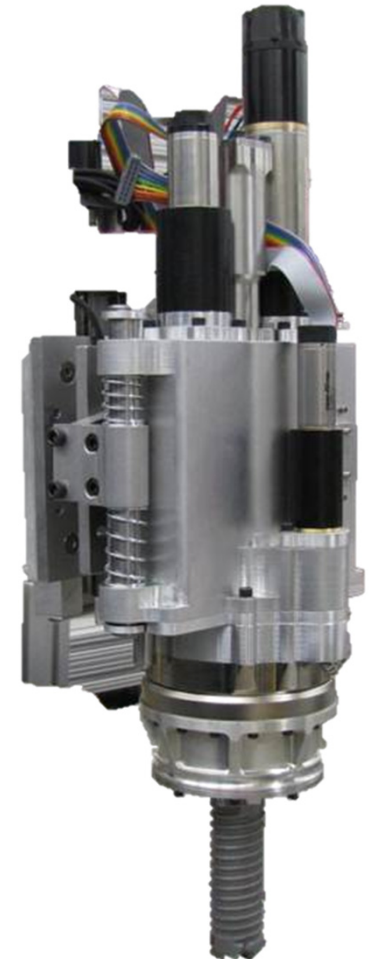
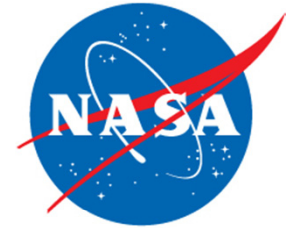
## Conclusion

The **Sample Acquisition Tool (SAT)** is designed for autonomous:

- coring
- core fracture/retention
- bit change-out

SAT is a less complex coring tool design than what has previously been proposed:

- TDD can be used for tool feed
- Reduced tool preload





Introduction

Hardware  
Development

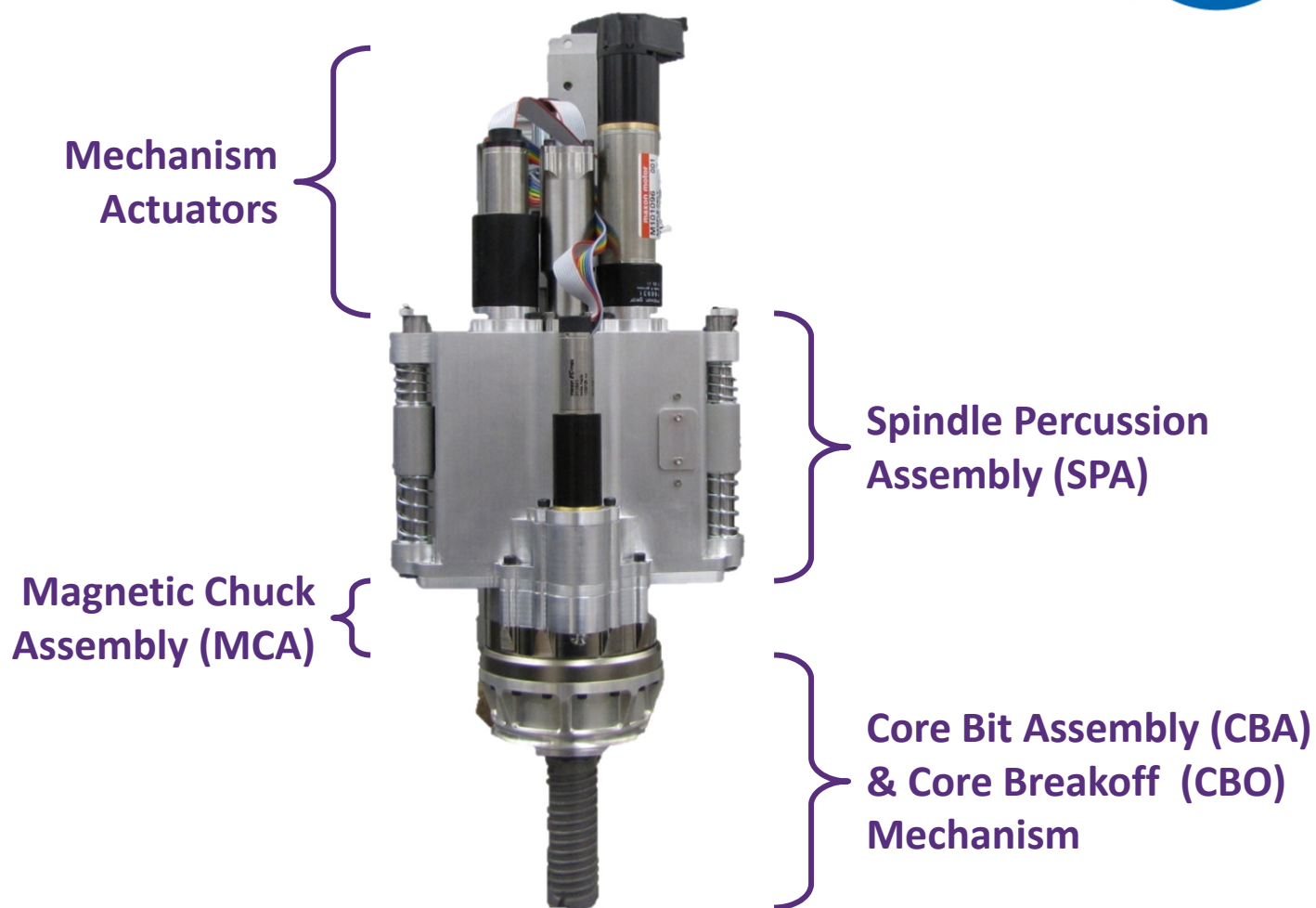
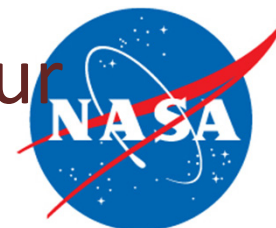
Lessons Learned  
– Hardware Dev

Test Results

Lessons Learned  
– Unit Testing

Conclusion

The **SAT** design is comprised of four main subassemblies



## Introduction

## Hardware Development

## Lessons Learned – Hardware Dev

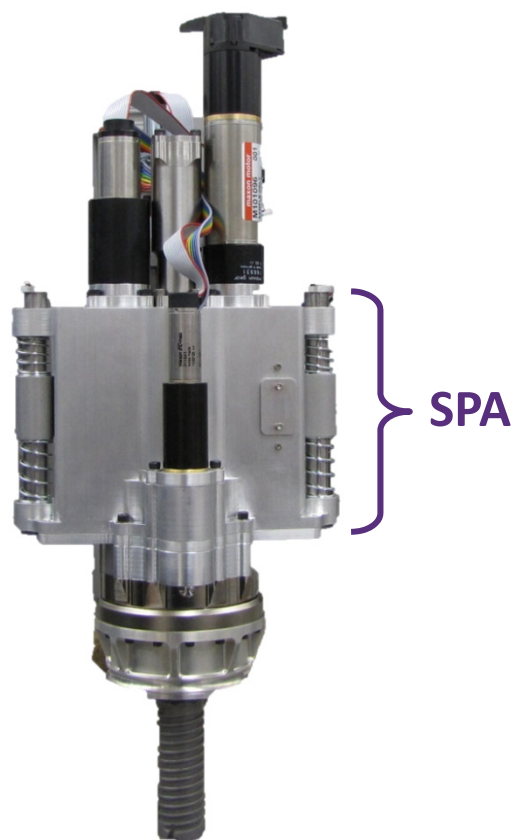
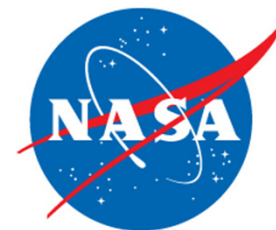
## Test Results

## Lessons Learned – Unit Testing

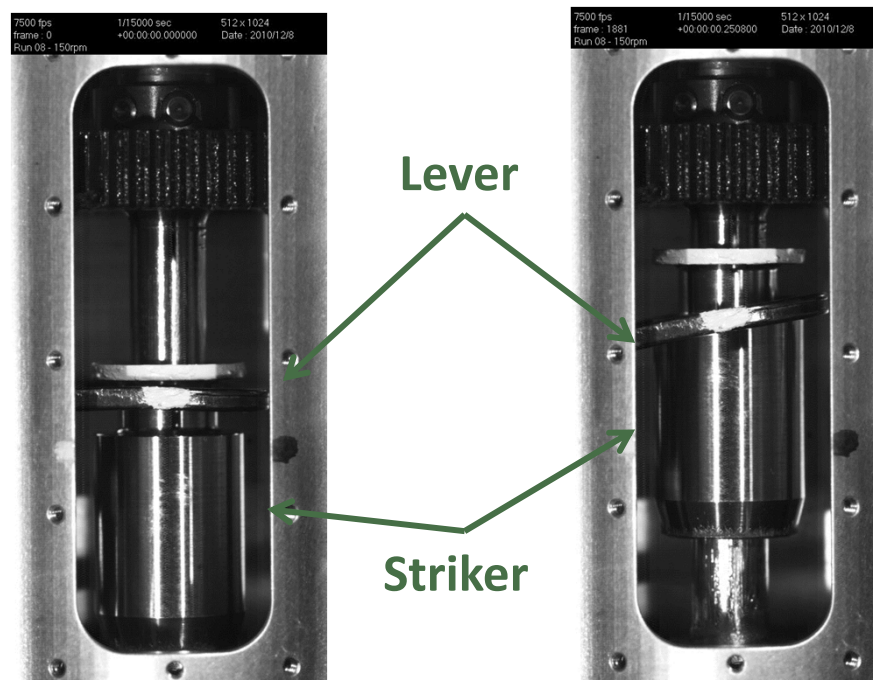
## Conclusion

The **Spindle Percussion Assembly (SPA)** provides:

- rotational DOF to drive the CBA
- axial motion to drive the percussion striker mass



Percussion striker shown thru full range of motion



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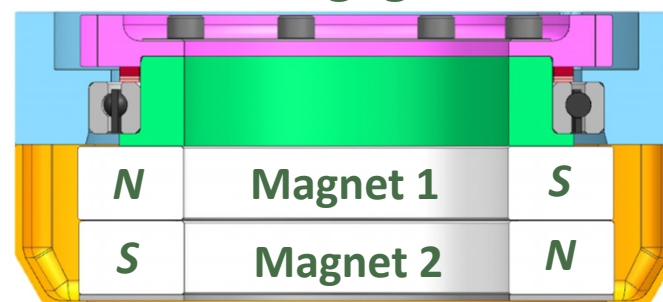
## Conclusion

The **Magnetic Chuck Assembly (MCA)** utilizes two diametrically polarized permanent magnets

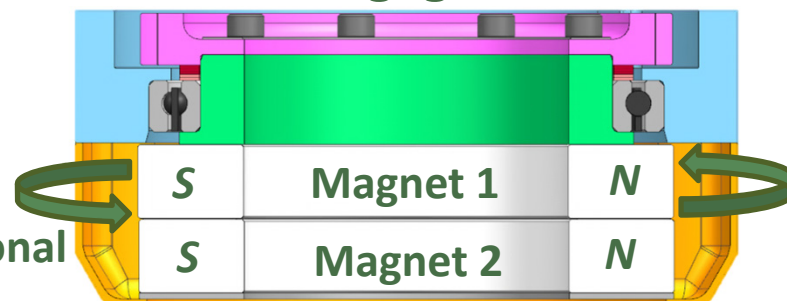
- Passive release of CBA under predefined side and/or axial loads



Disengaged



Engaged



Rotational  
DOF



## Introduction

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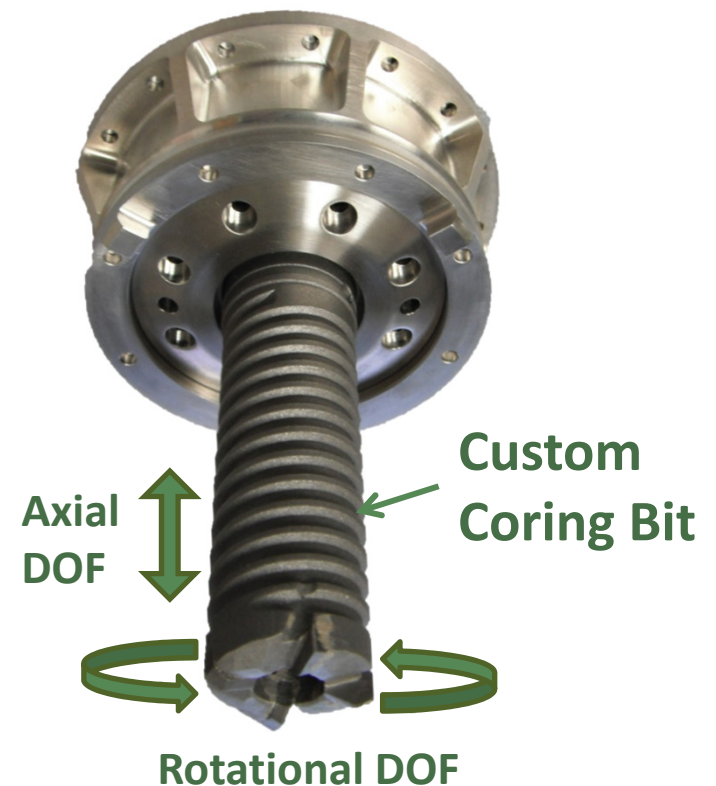
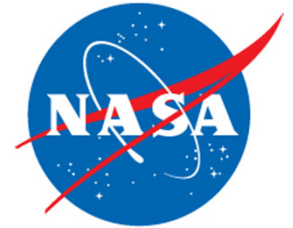
## Test Results

## Lessons Learned – Unit Testing

## Conclusion

The **Core Bit Assembly (CBA)** uses a custom coring bit that functionally:

- allows engagement with the magnetic chuck
- accepts the rotational DOF from the SPA
- allows for an axial DOF for maximum transmission of impact energy



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## Hardware Development

## Lessons Learned – Hardware Dev

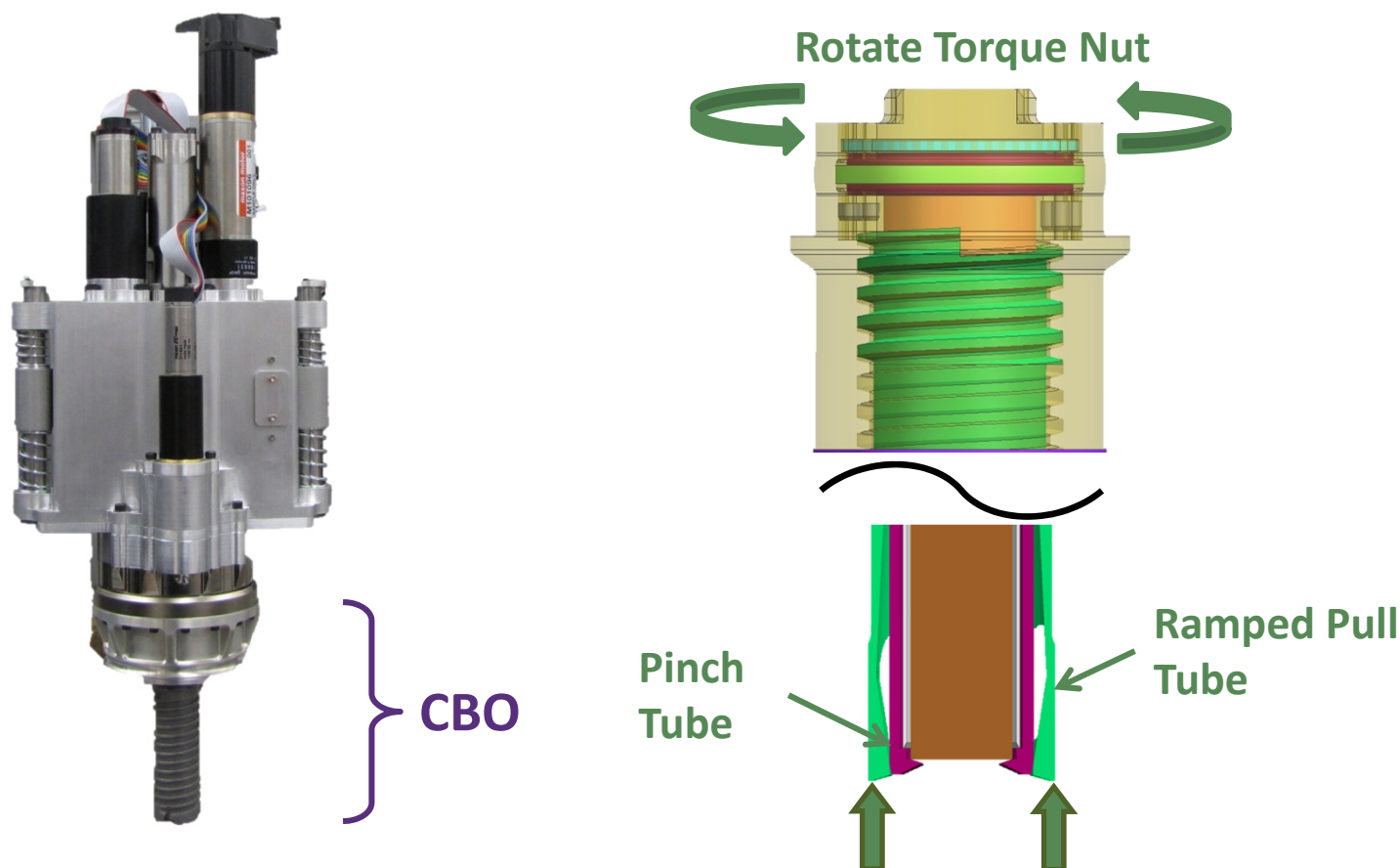
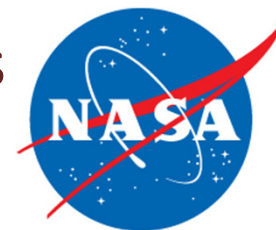
## Test Results

## Lessons Learned – Unit Testing

## Conclusion

The **Core Breakoff (CBO)** mechanism uses a cleaving approach for core fracture

- allows for a well-controlled and predictable fracture plane



## Introduction

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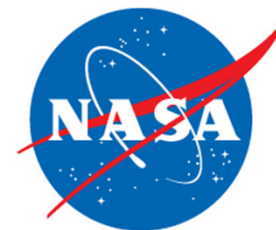
## Lessons Learned – Hardware Dev

## Test Results

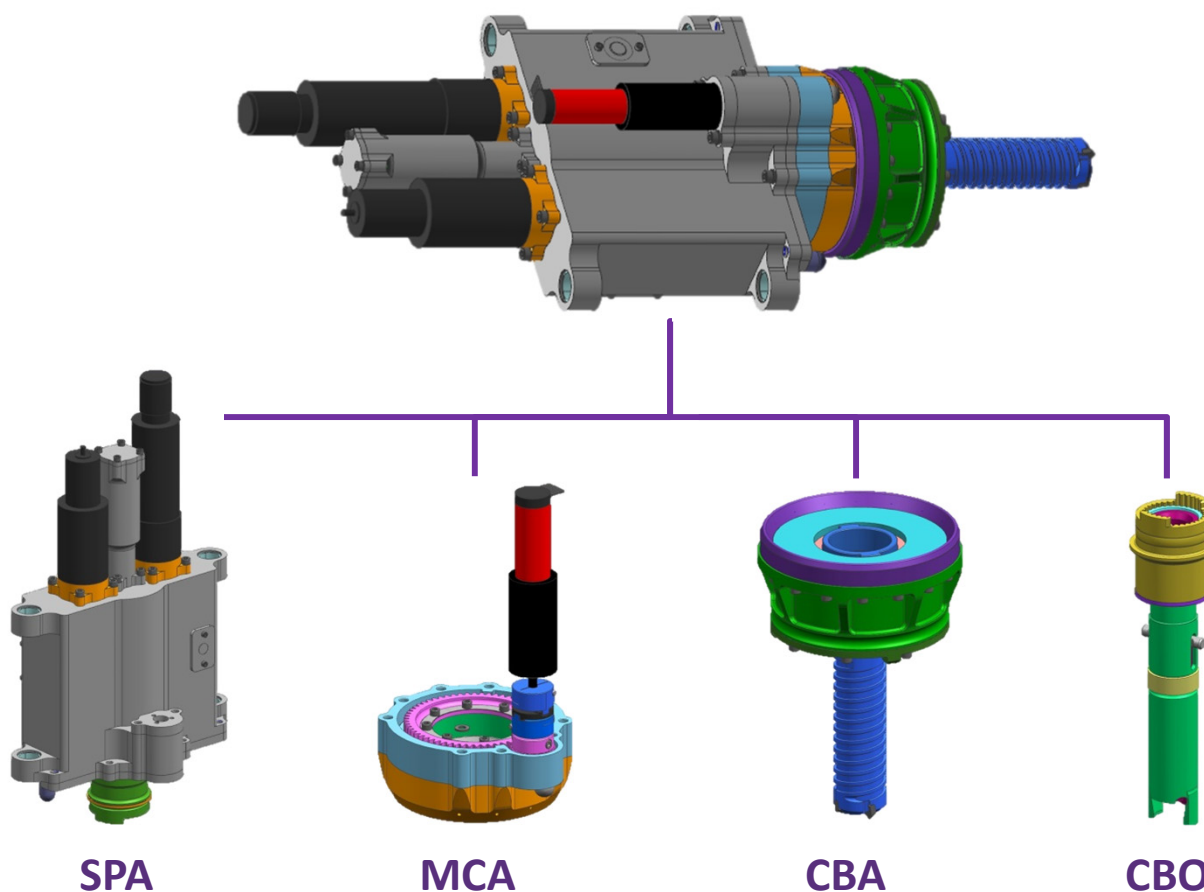
## Lessons Learned – Unit Testing

## Conclusion

Overall **tool design philosophy** driven by schedule and resource limitations



Using *lesson learned from MSL Drill development*, tool design was implemented using a modular approach



## Introduction

## Hardware Development

## Lessons Learned – Hardware Dev

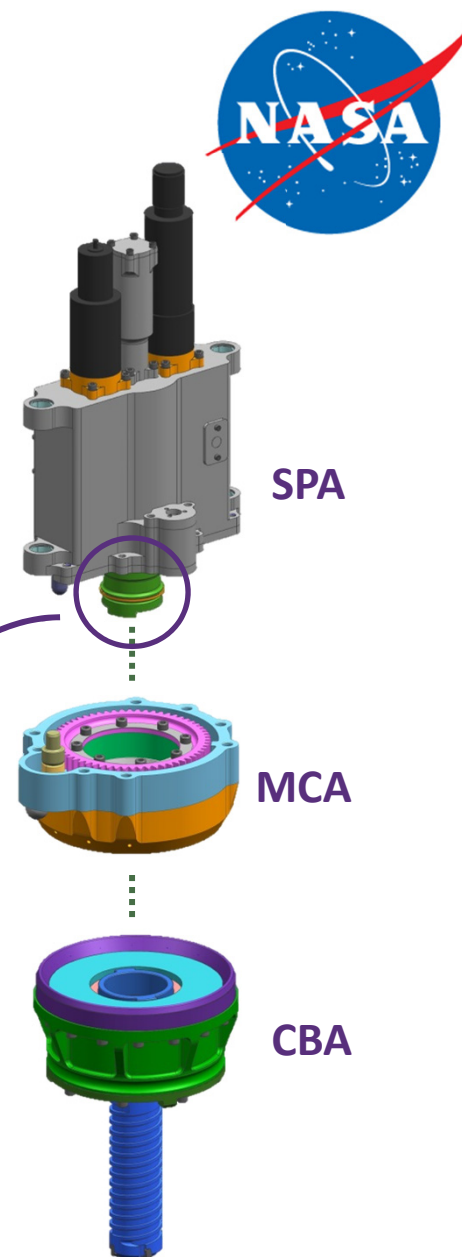
## Test Results

## Lessons Learned – Unit Testing

## Conclusion

Novel chuck approach required **compromises** in material selection for torque couplings

**Lesson Learned** – anticipate impact of compromises early in design to allow for possible mitigation paths



## Introduction

## Hardware Development

## Lessons Learned – Hardware Dev

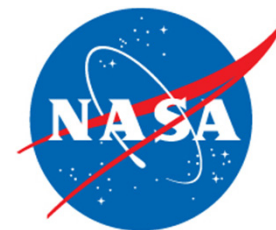
## Test Results

## Lessons Learned – Unit Testing

## Conclusion

**Modular design approach** can accommodate interface growth relatively easily between sub-assemblies

**Lesson Learned** – remember the big picture! Interface growth at the sub-assembly level may result in failure to satisfy system level constraints and requirements



**Minimum clearance at full depth hole**



## Introduction

## Hardware Development

## Lessons Learned – Hardware Dev

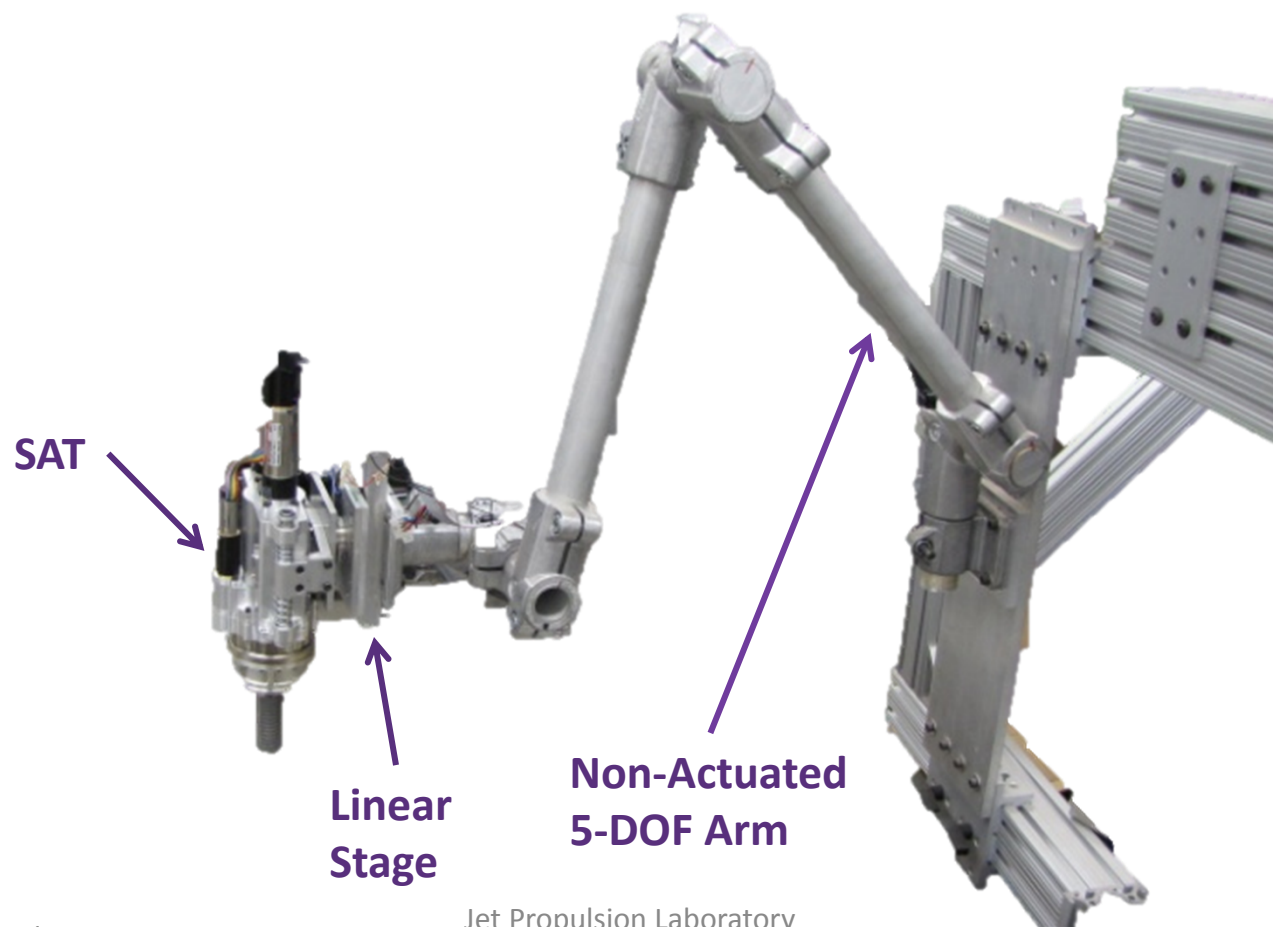
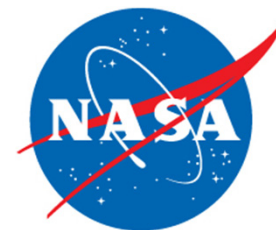
## Test Results

## Lessons Learned – Unit Testing

## Conclusion

### SAT assembly level test configuration

- Surrogate arm allowed for realistic boundary conditions
- No arm force feedback
- Used a linear stage for linear feed
- Used a force sensor for controlling weight on bit



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Hardware  
Development

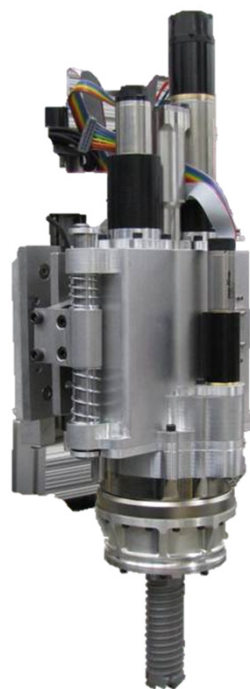
Lessons Learned  
– Hardware Dev

Test Results

Lessons Learned  
– Unit Testing

Conclusion

# Tool verification performed using analogous Martian rock test suite



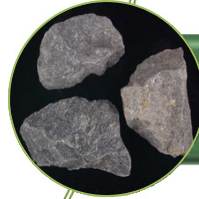
Kaolinite



Limestone



Siltstone



Saddleback Basalt



Volcanic Breccia

Introduction

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Conclusion

# End-to-end unit level testing: core generation, fracture, and capture



**Kaolinite**  
• Intact cores



**Limestone**  
• Mostly intact cores



**Siltstone**  
• Segmented disks



**SB Basalt**  
• Mostly intact cores



**V. Breccia**  
• Mostly intact cores

## Introduction

## Hardware Development

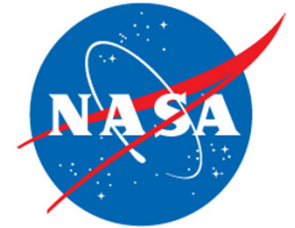
## Lessons Learned – Hardware Dev

## Test Results

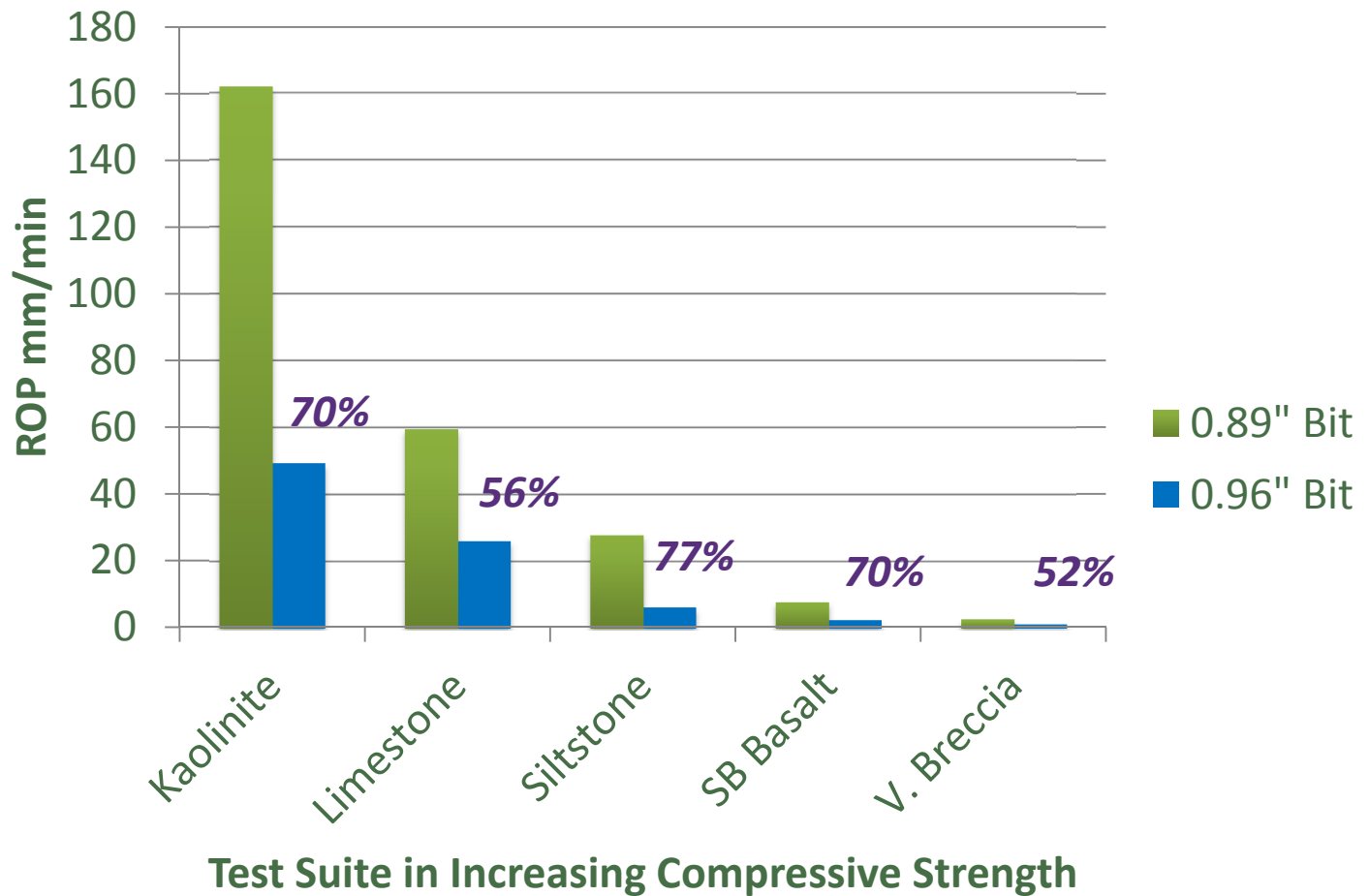
## Lessons Learned – Unit Testing

## Conclusion

**Lesson Learned** – For development efforts with low maturity levels, emphasis should be placed on understanding performance sensitivities



### ROP Sensitivity



## Introduction

## Hardware Development

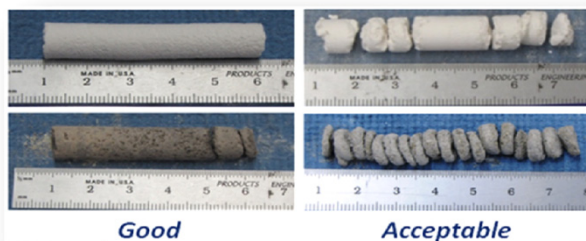
## Lessons Learned – Hardware Dev

## Test Results

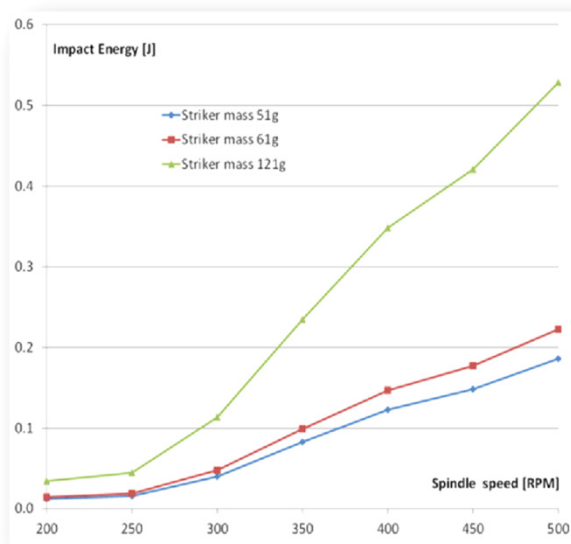
## Lessons Learned – Unit Testing

## Conclusion

# Lessons Learned from unit level testing



Linked mechanisms result in reduced operational flexibility to investigate operational parameters vs. tool performance

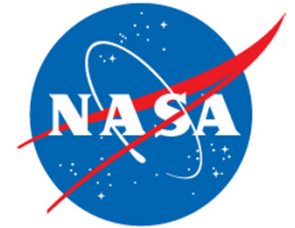


For early proof of concept development efforts, focus energies on providing for large capability margins rather than design optimization approaches



## Introduction

**Successfully** demonstrated a low mass coring tool for autonomous core generation, fracture, and capture



## Hardware Development

Modular design approach selected due to schedule and resource constraints

## Lessons Learned – Hardware Dev

For early development efforts:

- Pursuing de-coupled mechanism provides greater flexibility in terms of identifying operational parameter needs vs. performance
- Greater emphasis should be placed on understanding design sensitivities rather than design optimization

## Test Results

## Lessons Learned – Unit Testing

## Conclusion



Questions?